

IN THE CLAIMS:

Please cancel claim 1 without prejudice or disclaimer;

Please amend claims 2, 5, and 7 as follows.

1. (Cancelled)

2. (Currently Amended) A robot hand apparatus, comprising:

a plurality of finger mechanisms each elongates from a base;

a power source actuating each finger mechanism;

a plurality of finger mechanism actuation units for actuating each finger mechanism; and

a power transmission mechanism transmitting a power from the power source to at least two of said plurality of finger mechanisms at different timing.~~A robot hand apparatus according to claim 1,~~

wherein the power source is a motor,

the finger mechanism actuation unit is a rotation roller which connects with the finger mechanism through a transmission unit,

the power transmission mechanism comprises

a rotation axis which supports each rotation roller while allowing the rotation of the rotation roller and is rotated by the motor, and

elastic devices, each is fixed to the rotation axis for holding the rotation roller at a predetermined position on the rotation axis, wherein

each rotation roller rotates together with the rotation axis when the rotation roller is held at a predetermined position on the rotation axis by the elastic device, and wherein the degree of the deformation of each of elastic devices differs each other, when the finger mechanism is in a maximum grip state or in a maximum stretch state.

3. (Original) A robot hand apparatus according to claim 2, wherein the transmission unit is a link mechanism.

4. (Previously Presented) A robot hand apparatus according to claim 2, wherein a plurality of contact-parts, each engages with and separates from a part of the corresponding rotation roller, are provided on the rotation axis.

5. (Currently Amended) A robot hand apparatus according to claim 2, wherein each finger mechanism is supported while allowing the turn in an approaching-and-separating direction with regard to the adjoining finger mechanism around a base-side section of the finger mechanism.

6. (Original) A robot hand apparatus according to claim 4, wherein each finger mechanism is supported while allowing the turn in an approaching-and-separating direction with regard to the adjoining finger mechanism around a base-side section of the finger mechanism.

7. (Currently Amended) A robot hand apparatus according to claim 2~~1~~, wherein the finger mechanism is held by an elastic device fixed to the base, and the finger mechanism is pushed by the elastic device in a direction apart from the adjoining finger mechanism.

8. (Original) A robot hand apparatus according to claim 4, wherein the finger mechanism is held by an elastic device fixed to the base, and the finger mechanism is pushed by the elastic device in a direction apart from the adjoining finger mechanism.

9. (Original) A robot hand apparatus according to claim 5, wherein the finger mechanism is held by an elastic device fixed to the base, and the finger mechanism is pushed by the elastic device in a direction apart from the adjoining finger mechanism.

10. (Original) A robot hand apparatus according to claim 6, wherein the finger mechanism is held by an elastic device fixed to the base, and the finger mechanism is pushed by the elastic device in a direction apart from the adjoining finger mechanism.